IN THE CLAIMS

This listing of the claim will replace all prior versions and listings of claim in the present application.

Listing of Claims

Claims 1-14 (canceled).

15. (currently amended) An object detecting method for detecting an object in an image obtained from an image pickup means, comprising:

a frame subtraction step of executing a plurality of frame subtraction ~~processing~~ processings each frame subtraction processing being between an input image from the image pickup means and respective ones of a plurality of images each having a different time interval with respect to the time interval of said input image;

a synthesizing step of adding together a plurality of differential ~~data~~ images obtained by said frame subtraction ~~processing~~ processings based on coefficients which are set for respective ones of predetermined regions of the image; and

an object detecting step of detecting an object based on data obtained from said synthesizing step.

16. (previously presented) An object detecting method according to claim 15, wherein said coefficients are set based on a distance from the image pickup means.

17. (previously presented) An object detecting method according to claim 15, wherein said coefficients are set based on a magnitude

of movement of an object in a respective one of predetermined regions of said image.

18. (currently amended)An object detecting method for detecting an object in an image obtained from an image pickup means, comprising:

a frame subtraction step of executing a plurality of frame subtraction ~~processing~~ processings each frame subtraction processing being for each of a plurality of predetermined regions ~~of the image obtained from the image pickup means~~,

wherein each of the predetermined regions has a frame time interval which is changed from the frame time intervals of each of the other predetermined regions; and

an object detecting step of detecting an object based on a plurality of differential ~~data~~ images obtained from said frame subtraction ~~processing~~processings.

19. (previously presented) An object detecting method according to claim 18, wherein said frame time interval is set based on a distance from said image pickup means.

20. (previously presented) An object detecting method according to claim 18, wherein said frame time interval is set based on a magnitude of movement of an object tin respective one of predetermined regions of said image.

21. (currently amended)An object detecting apparatus for detecting an object in an image obtained from image pickup means, comprising:

frame subtraction means for executing a plurality of frame subtraction ~~processing~~ processings each frame subtraction processing being between an input image from the image pickup means and respective ones of a plurality of images each having a different time interval with respect to the time interval of said input image;

synthesizing means for adding together a plurality of differential ~~data~~ images obtained by said frame subtraction ~~processing~~ processings based on coefficients which are set for respective ones of predetermined regions of the image; and

object detecting means for detecting an object based on data obtained from said synthesizing means.

22. (previously presented) An object detecting apparatus according to claim 21, wherein said coefficients are set based on a distance from said image pickup means.

23. (previously presented) An object detecting apparatus according to claim 21, wherein said coefficients are set based on a magnitude of movement of an object in respective one of predetermined regions of said image.

24. (currently amended)An object detecting apparatus for detecting an object in an image obtained from an image pickup means, comprising:

frame subtraction means for executing a plurality of frame subtraction ~~processing~~ processings each frame subtraction processing being for each of a plurality of predetermined regions ~~of the image obtained from the image pickup means~~,

wherein each of the predetermined regions has a frame time interval which is changed from the frame time intervals of each of the other predetermined regions; and

object detecting means for detecting an object based on a plurality of differential ~~data~~ images obtained from said frame subtraction processings performed by said frame subtraction means.

25. (previously presented) An object detecting apparatus according to claim 24, wherein said frame time interval is set based on a distance from said image pickup means.

26. (previously presented) An object detecting apparatus according to claim 24, wherein said frame time interval is set based on a magnitude of movement of an object in a respective one of the predetermined regions of said image.